

CLAIMS

1. A leg type mobile robot comprising:

an body;

5 legs each connected to the body via a first joint; and
foots each connected to an end part of the leg via a second
joint, wherein the foot includes

at least one foot portion, which has a ground area to be
grounded on a floor surface at the bottom thereof, and

10 a floor reaction force detector for detecting floor
reaction force acting from a floor surface through the foot
portion, and wherein

the center (P_c) of the second joint is offset against the
position P_a in a plane view, the position P_a is the position
15 where the distance to the remotest point of at least one ground
area becomes minimum, and the center (P_b) of the floor reaction
force detector is provided so that the center P_b is in the
vicinity of the position P_a than the center P_c of the ankle joint
in a plane view.

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2. A leg type mobile robot according to claim 1, wherein
the center (P_b) of the floor reaction force detector is
offset to a rear direction with respect to the position (P_a).

25 3. A leg type mobile robot according to claim 2, wherein
the center (P_b) of the floor reaction force detector is

positioned on a line segment connecting the position (Pa) and the center (Pc) of the second joint.

4. A leg type mobile robot according to claim 1, wherein
5 the center (Pb) of the floor reaction force detector is offset to a rear direction in a center side of the leg type mobile robot with respect to the position (Pa).

5. A leg type mobile robot according to claim 4, wherein
10 the center (Pb) of the floor reaction force detector is located on the perpendicular taken down from the center (Pc) of the second joint to the line segment extended from the position (Pa) to a rear direction.

15 6. A leg type mobile robot according to claim 4, wherein the center (Pb) of the floor reaction force detector is located on the perpendicular taken down from the center (Pc) of the second joint to the line segment extended from the position (Pa) to a center of the leg type mobile robot.

20 7. A leg type mobile robot according to claim 4, wherein the center (Pb) of the floor reaction force detector is positioned on a line segment connecting the position (Pa) and the center (Pc) of the second joint.

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